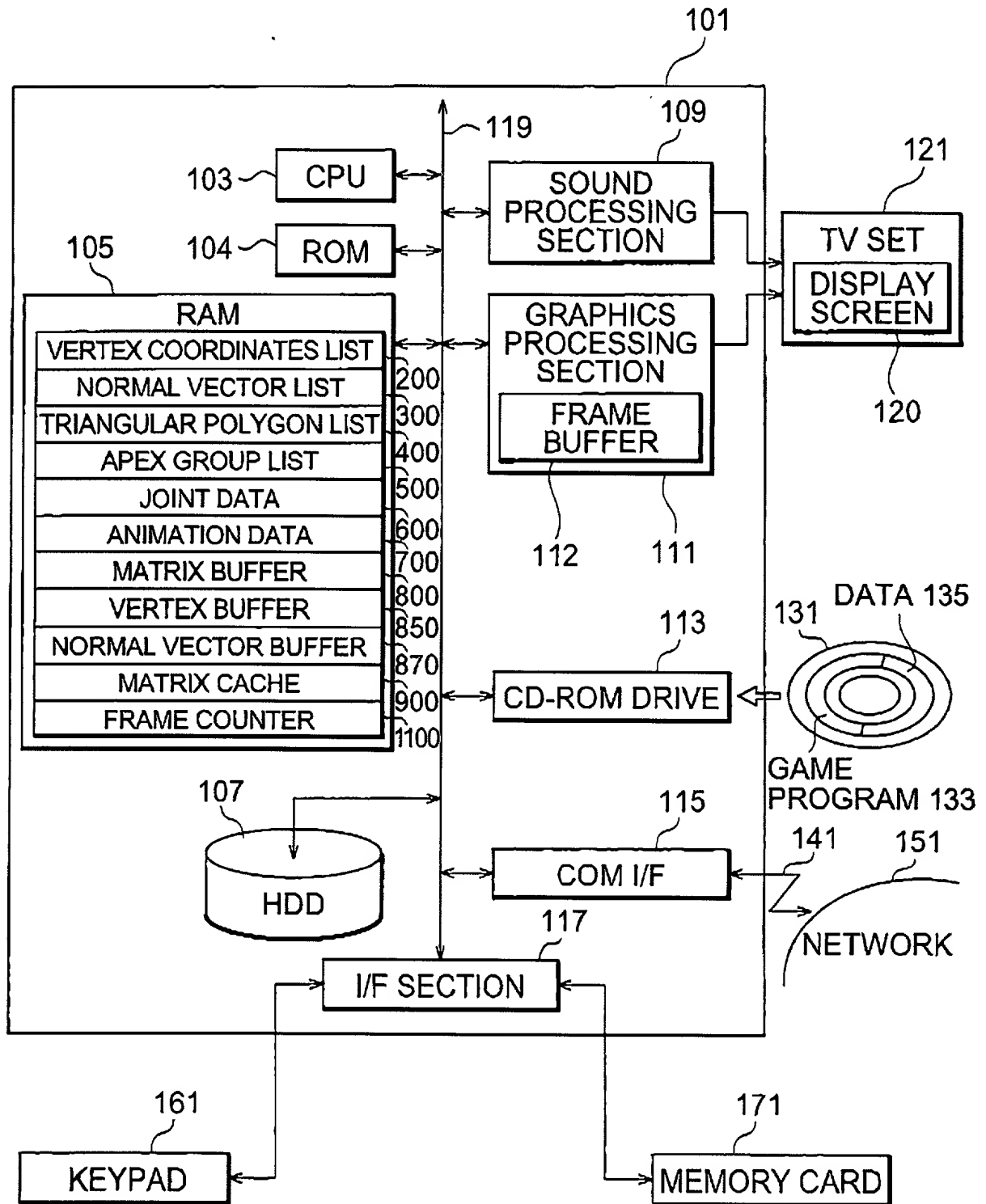


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Fig.1

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Fig.2

210 200 220

INDEX	COORDINATES (x,y,z)
vtx0	(0 , 0 , 0)
vtx1	(0 , 0 , 100)
vtx2	(0 , 100 , 0)
vtx3	(0 , 100 , 100)
vtx4	(100 , 0 , 0)
⋮	⋮

Fig.3

310 300 320

INDEX	NORMAL VECTOR (x,y,z)
nml0	(1 , 0 , 0)
nml1	(-1 , 0 , 0)
nml2	(0 , 0 , -1)
nml3	(-1 , -1 , 0)
nml4	(0 , -1 , 0)
⋮	⋮

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Fig.4

400

410 INDEX	420 VERTEX 0	430 VERTEX 1	440 VERTEX 2
plg0	vtx0 / nml0	vtx1 / nml2	vtx2 / nml3
plg1	vtx0 / nml1	vtx2 / nml3	vtx3 / nml4
⋮	⋮	⋮	⋮

Fig.5

500

VERTEX GROUP LIST

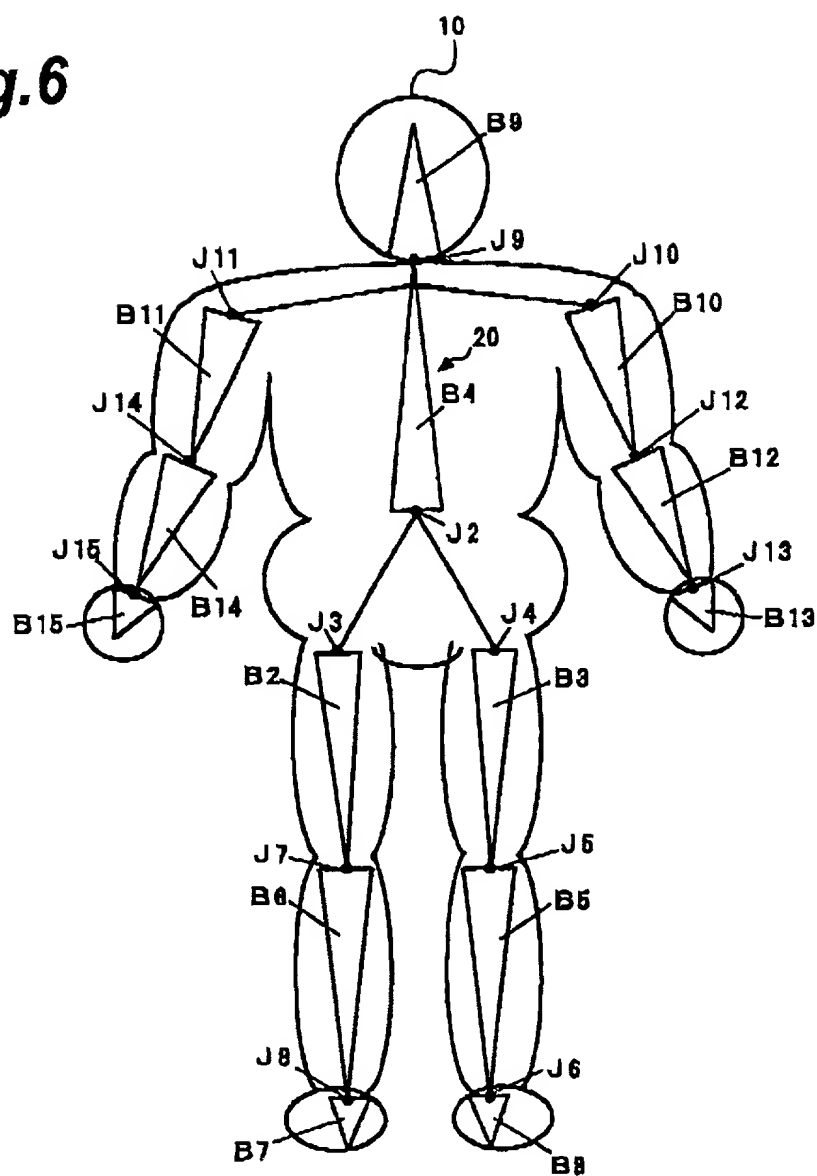
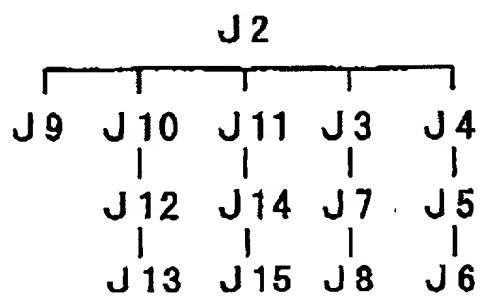
510	NUMBER OF GROUPS	3							
520	NUMBER OF MEMBERS	4							
530	VERTEX	vtx1	WEIGHT (540)	1.0	NUMBER OF NORMALS(570)	2	NORMALS (591)	nml0	nml1
532	VERTEX	vtx2	WEIGHT (542)	1.0	NUMBER OF NORMALS(572)	1	NORMALS (592)	nml10	
534	VERTEX	vtx3	WEIGHT (544)	1.0	NUMBER OF NORMALS(574)	1	NORMALS (593)	nml2	
536	VERTEX	vtx4	WEIGHT (546)	1.0	NUMBER OF NORMALS(576)	2	NORMALS (594)	nml3	nml1
522	NUMBER OF MEMBERS	4							
550	VERTEX	vtx5	WEIGHT (560)	0.5	NUMBER OF NORMALS(580)	1	NORMALS (595)	nml11	
552	VERTEX	vtx6	WEIGHT (562)	0.5	NUMBER OF NORMALS(582)	1	NORMALS (596)	nml4	
554	VERTEX	vtx7	WEIGHT (564)	1.0	NUMBER OF NORMALS(584)	1	NORMALS (597)	nml5	
556	VERTEX	vtx8	WEIGHT (566)	1.0	NUMBER OF NORMALS(586)	3	NORMALS (598)	nml6	nml8 nml9
524	NUMBER OF MEMBERS	1							
558	VERTEX	vtx7	WEIGHT (568)	0.5	NUMBER OF NORMALS(588)	1	NORMALS (599)	nml7	

VERTEX GROUP 0

VERTEX GROUP 1

VERTEX GROUP 2

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Fig.6**Fig.7**

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Fig.8

600

610	Root index	root	
612	Basic parallel movement amount (x, y, z)	(0, 0, 0)	
614	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 90)	
616	Number of joints	4	
620	Joint index	Joint0	Joint 0
622	Parent index	root	
624	Basic parallel movement amount (x, y, z)	(90, 20, 0)	
626	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 135)	
628	Number of vertex groups	2	
630	Vertex group number	0	
632	Vertex group number	2	
640	Joint index	Joint1	Joint 1
642	Parent index	Joint0	
644	Basic parallel movement amount (x, y, z)	(40, 0, 0)	
646	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 45)	
648	Number of vertex groups	1	
650	Vertex group number	1	

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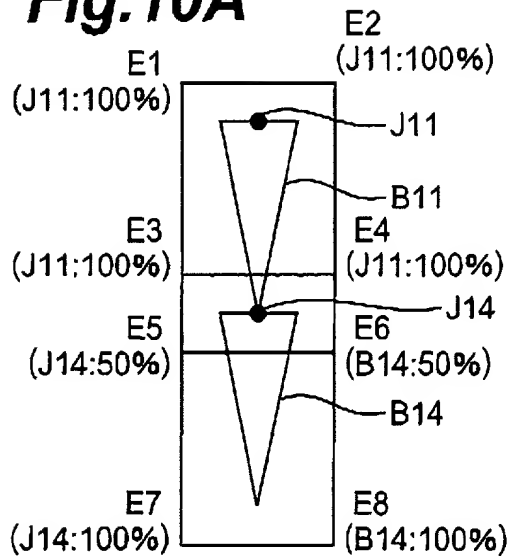
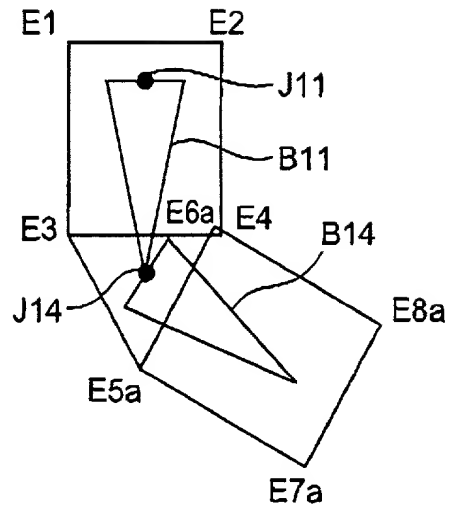
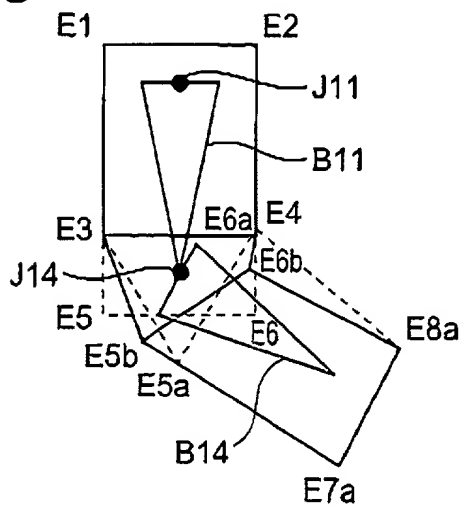
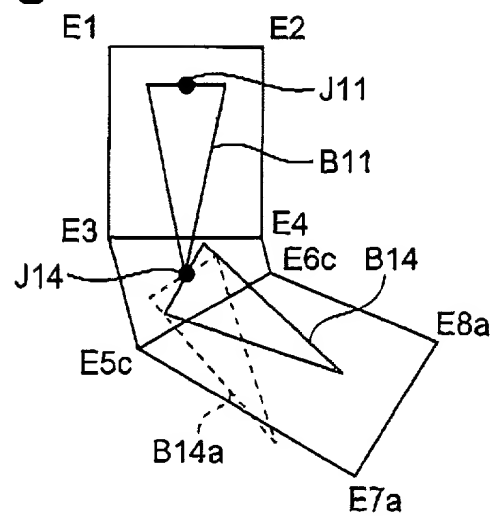
Fig.9A

Number of joints	Number of frames
2	10

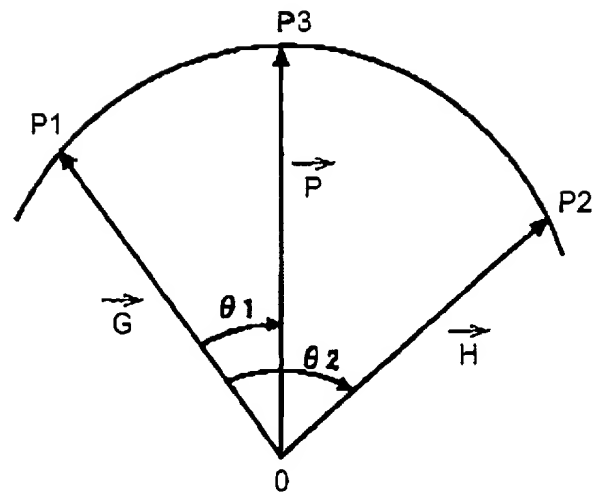
Fig.9B

Joint index	Rotation angle (Rx, Ry, Rz)	
Joint0	(0, 0, 0)	Frame0
Joint1	(0, 0, 0)	
Joint0	(10, 0, 135)	Frame1
Joint1	(-10, 5, 45)	
⋮	⋮	
Joint0	(90, 0, 150)	Frame9
Joint1	(-90, 45, 45)	

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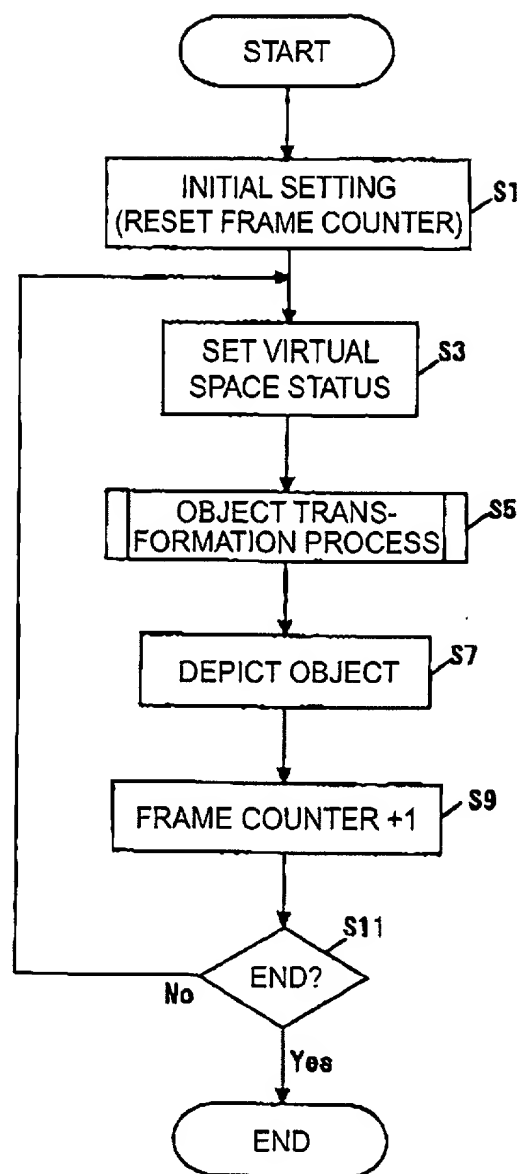
Fig.10A**Fig.10B****Fig.10C****Fig.10D**

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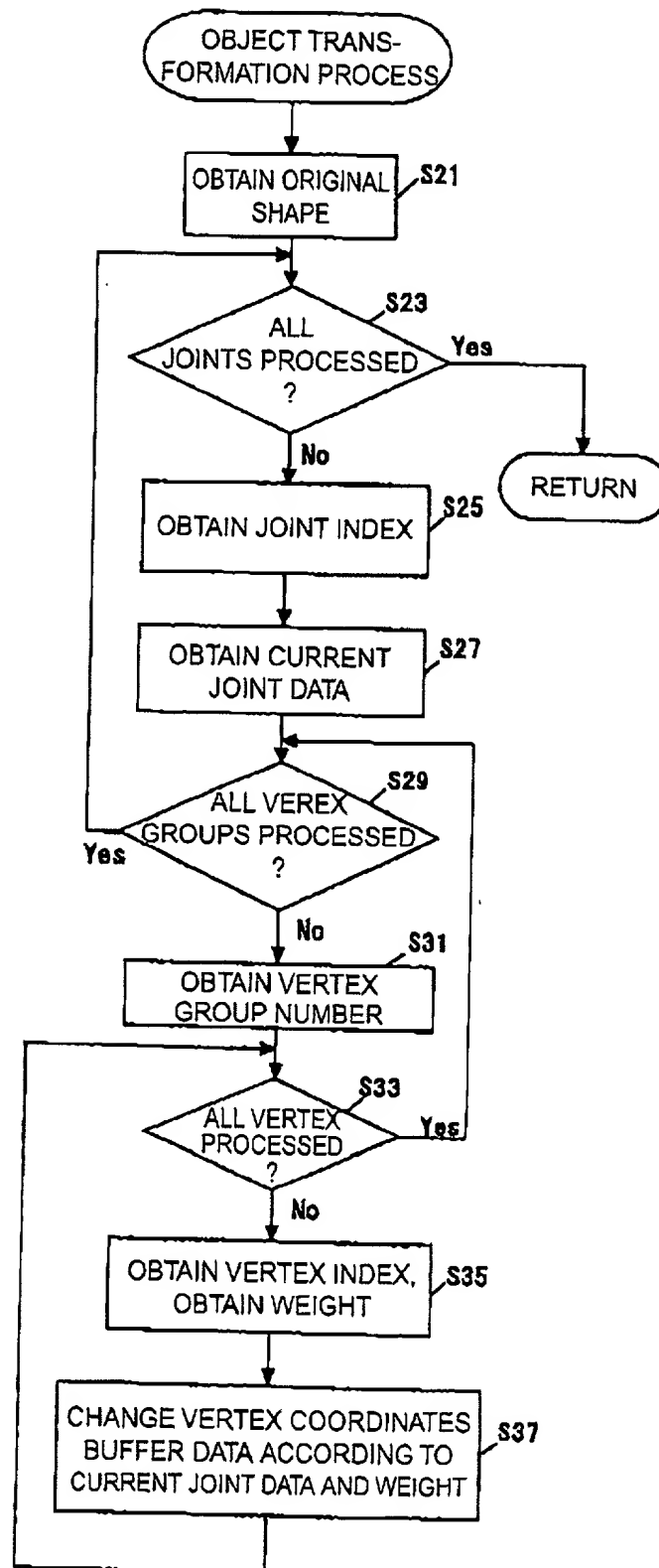
Fig.11

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Fig.12

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Fig.13

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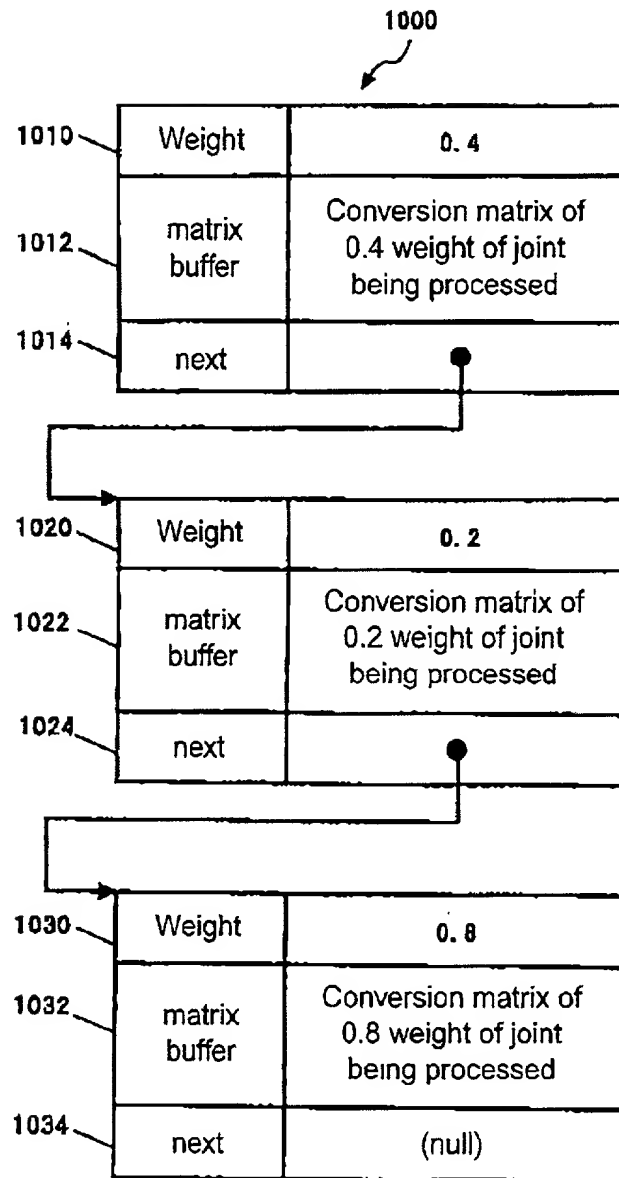
Fig.14

Joint index	Matrix data
root	Root conversion matrix
Joint0	Conversion matrix with 100% weight of joint0
Joint1	Conversion matrix with 100% weight of joint1

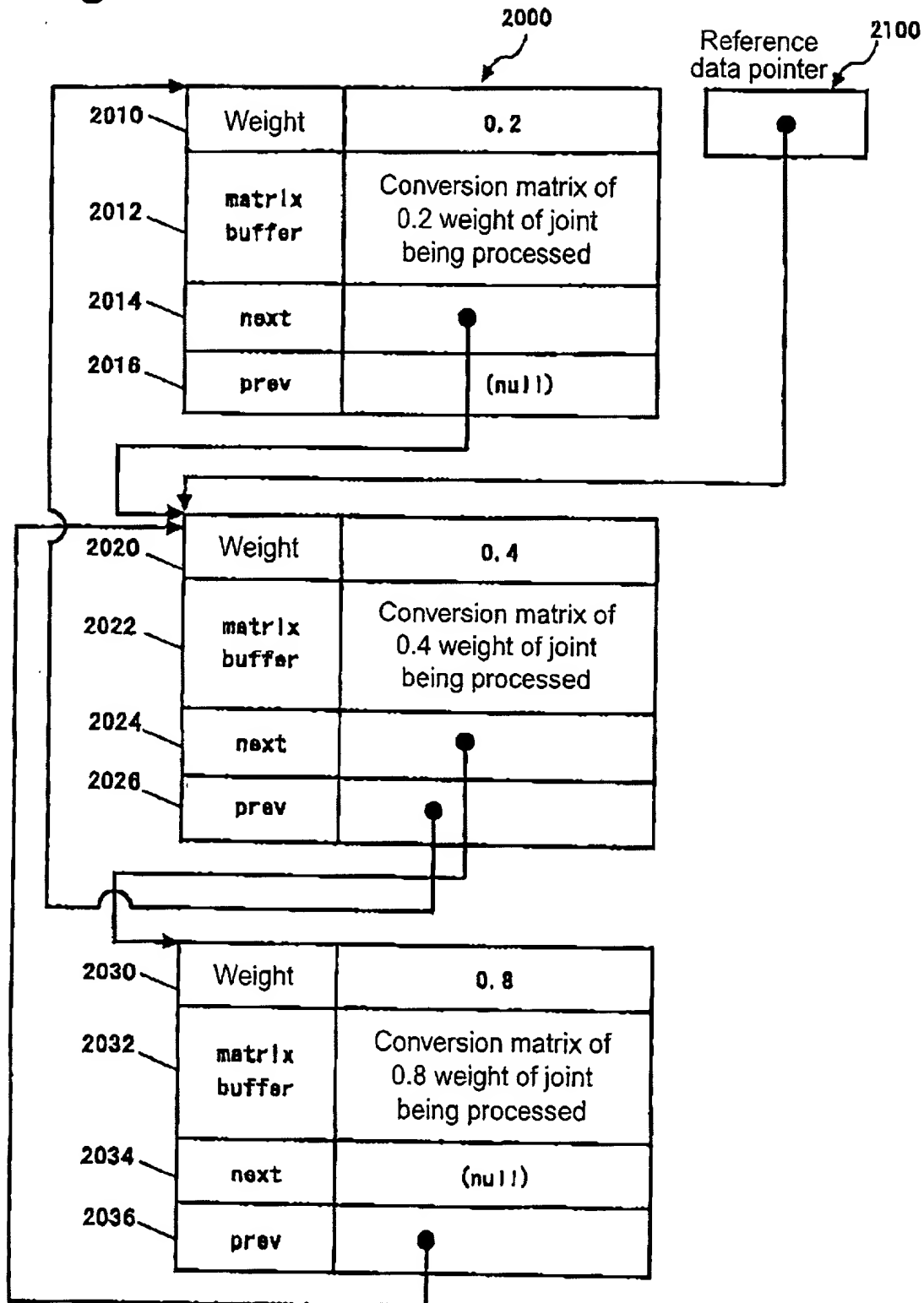
Fig.15

Weight	Weight
matrix buffer	Conversion matrix according to weight of joint being processed

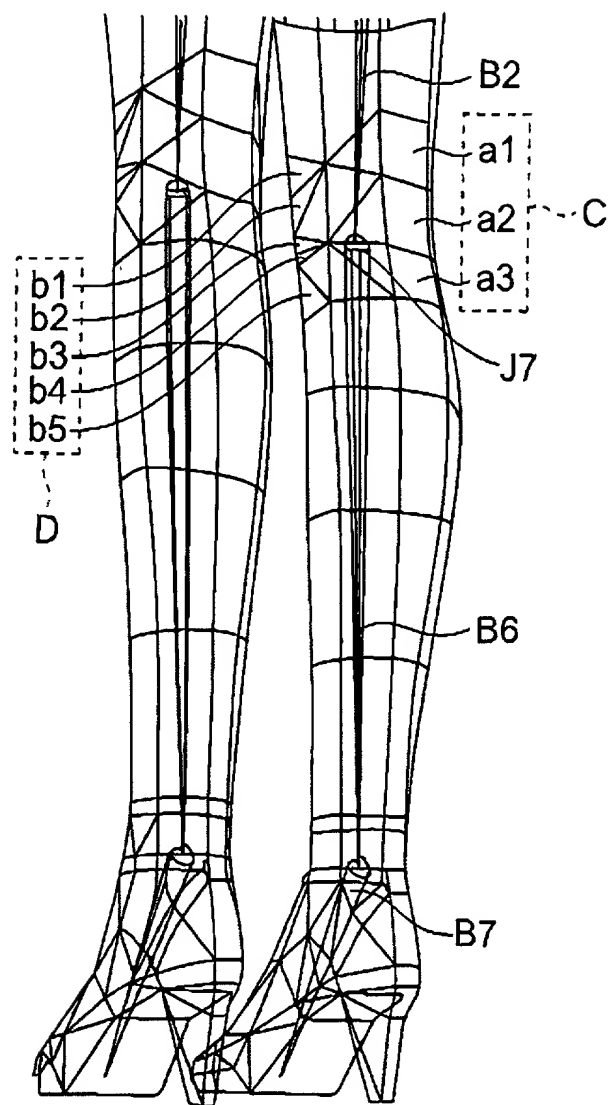
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Fig.16

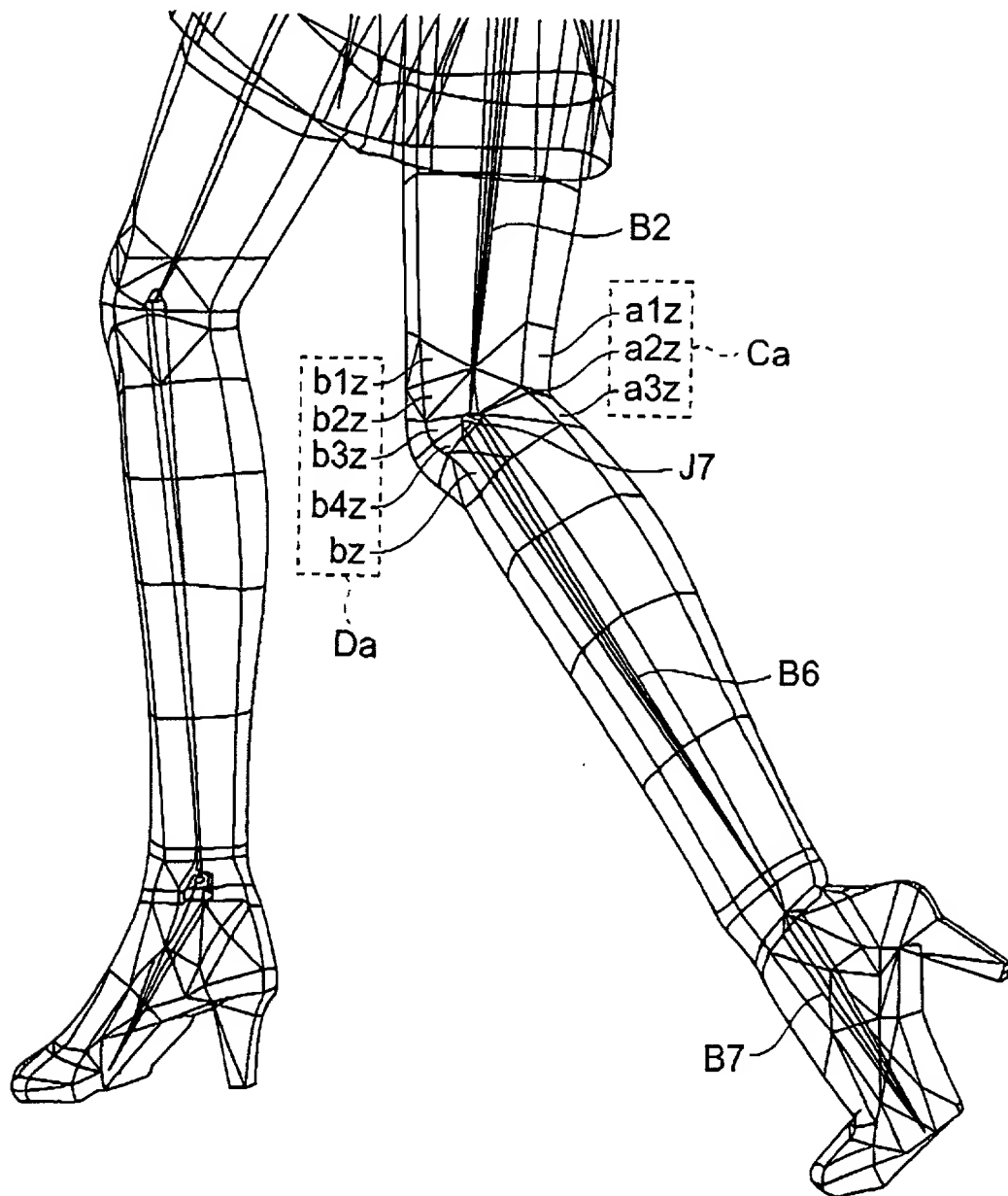
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Fig.17

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Fig.18

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Fig.19

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Fig.20



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Fig.21



120

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